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| US 20040165681 A1 | Narrow band chaotic frequency shift keying | 20040826 | 375/322 |
| US 20040164791 A1 | Nonlinear filter | 20040826 | 327/552 |
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| US 20040105510 A1 | Digital predistortion system for linearizing a power amplifier | 20040603 | 375/297 |
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| US 20040097557 A1 | Cyanothiophene derivatives, compositions containing such compounds and methods of use | 20040520 | 514/342 |
| US 20040097552 A1 | Cyanothiophene derivatives, compositions containing such compounds and methods of use | 20040520 | 514/336 |
| US 20040061687 A1 | Dynamic corrections for a non-linear touchscreen | 20040401 | 345/173 |
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| US 20040039555 A1 | System and method for stochastic simulation of nonlinear dynamic systems with a high degree of freedom for soft computing applications | 20040226 | 703/2 |
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| US 20040031918 A1 | Mass spectrometer with improved mass accuracy | 20040219 | 250/282 |
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| US 20030175239 A1 | Stabilized protein crystals, formulations comprising them and methods of making them | 20030918 | 424/85.1 |
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| US 20030120361 A1 | Process control system | 20030626 | 700/31 |
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| US 20030093392 A1 | System for intelligent control based on soft computing | 20030515 | 706/13 |
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| US 20020183290 A1 | Adrenergic receptor antagonists selective for both alpha1A-and alpha1D-subtypes and uses therefor | 20021205 | 514/169 |
| US 20020178193 A1 | Method for filtering signals from nonlinear dynamical systems | 20021128 | 708/300 |
| US 20020172297 A1 | Front end processor for data receiver and nonlinear distortion equalization method | 20021121 | 375/316 |

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| US 20020158843 A1 | Method and adapter for performing assistive motion data processing and/or button data processing external to a computer | 20021031 | 345/157 |
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it is convenient to introduce the concept of **Lyapunov** exponent. Let us consider the function g that

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quadratic correction term as the solution of a **Lyapunov** equation. Remarkably, this correction term can

in both continuous and combinatorial **optimization** (we refer the reader to [18] for an extensive

On the Nesterov-Todd direction in semidefinite **programming** M. J. Todd K. C. Toh y and R. H.

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quadratic correction requires the solution of a **Lyapunov** equation, but this can be solved explicitly and

and Applied Mathematics, SIAM Journal on **Optimization** 8 (1998) 769-796. Corresponding author.

On The Nesterov-Todd Direction In Semidefinite **Programming** #M. J. Todd K. C. Toh
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controllers is the search for adequate **Lyapunov** functions that establish stability and a [1]an elegant and solidly based branch of **optimization** theory [2, 3, 4]Expressed in terms of Linear

using available tools in convex semi-definite **programming**. When used together, these techniques provide

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the process. Monotonicity" is characterized by a **Liapunov** function, representing the "distance" to the set
approach has been taken in neural nets [18]**optimization**, graphical simulation [16] and robot control
Constraint **Programming** in Constraint Nets Ying Zhang Department of
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algorithm is initialized with a stochastic **Lyapunov** function, then the following hold i)A Value Iteration and **Optimization** of Multiclass Queueing Networks Rong-Rong decision processes, optimal control, dynamic **programming**. Work supported in part by NSF Grant ECS
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with symmetric interconnections possess natural **Liapunov** functions, and are thus at least dynamically 1 from the general theory of local search for **optimization** problems (Schaffer and Yannakakis 1991)In Colloquium on Automata, Languages, and **Programming**, Lecture Notes in Computer Science Vol. 700,
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control function to the next one. Motivated by **Liapunov** stability theory, M. Glaum [4] related algebraic Further, in their recent work (6]7]an **optimization** problem (with ffl-tolerance) is converted into (with ffl-tolerance) is converted into a linear **programming** problem based upon the discreet topology. In
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such method uses parameter-dependent quadratic **Lyapunov** functions and ideas drawn from **H1 optimization** theory, the synthesis problem reduces to convex **optimization** involving linear matrix inequalities. A and optimizing controllers reduces to convex **programming**. These controllers are also systematically
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$Qx = JNt$ where $\sim Q$ is the solution of the matrix **Lyapunov** equation $\sim Q = QK T R K A \backslash Gamma BK) T$ MPC which transforms an infeasible MPC **optimization** problem into a feasible one. The algorithm problem using the strategy of lexicographic goal **programming** where the objectives have different
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stabilizing controller by posing the following **optimization** [3] Pointwise Min-Norm minimize $u^T u$

, positive semi-definite. A standard dynamic **programming** argument reduces the above optimal control

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James A. Primbs

feasibility problems and complicate the on line **optimization** [16] On the other hand, obtaining stability

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where X is a

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are equal to the traces of the corresponding **Lyapunov** matrices $f_P \mid g_j \mid j \leq m$ as $j \leq 4$ $\in \mathbb{Z}$ 1 0

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